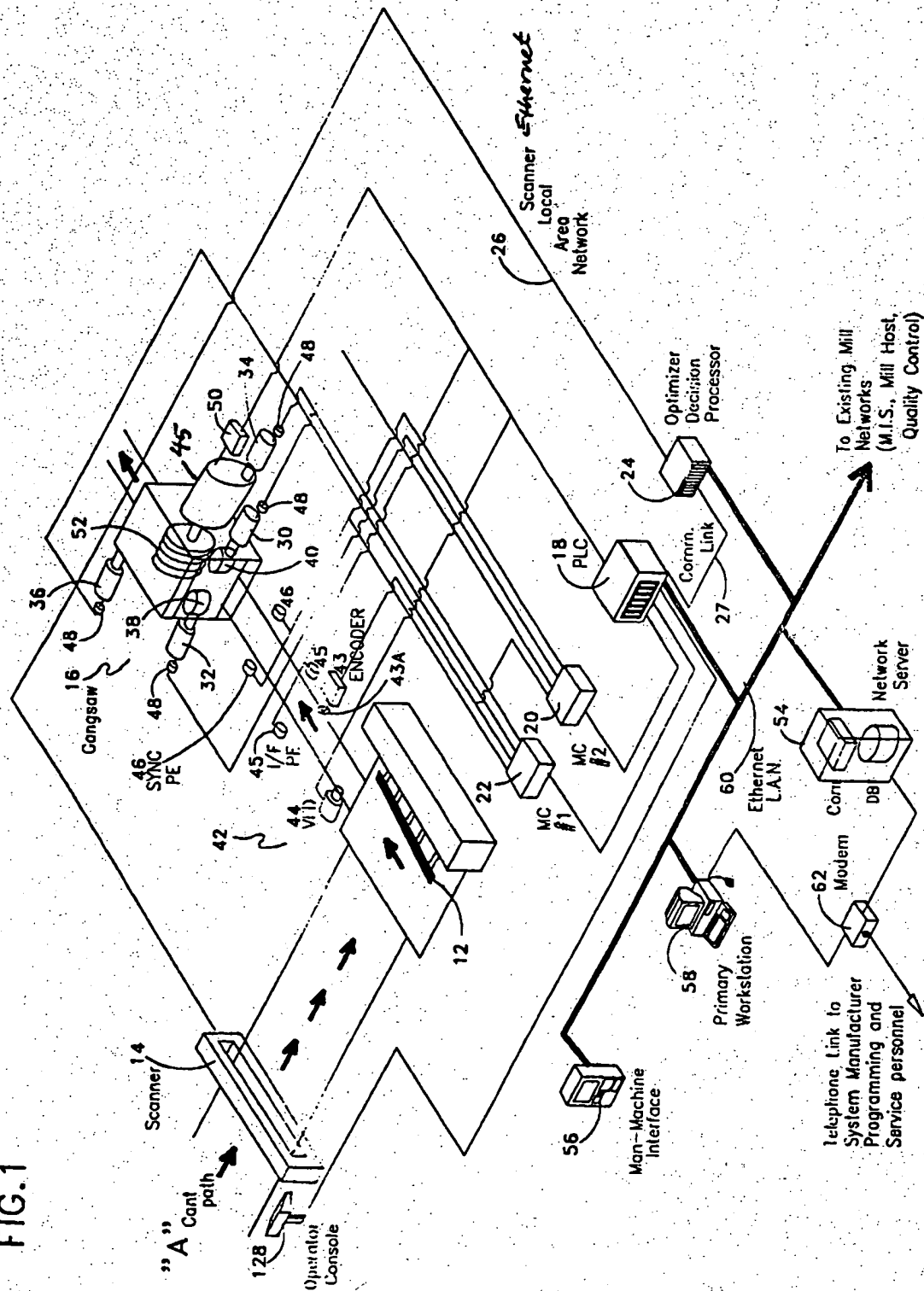


FIG. 1



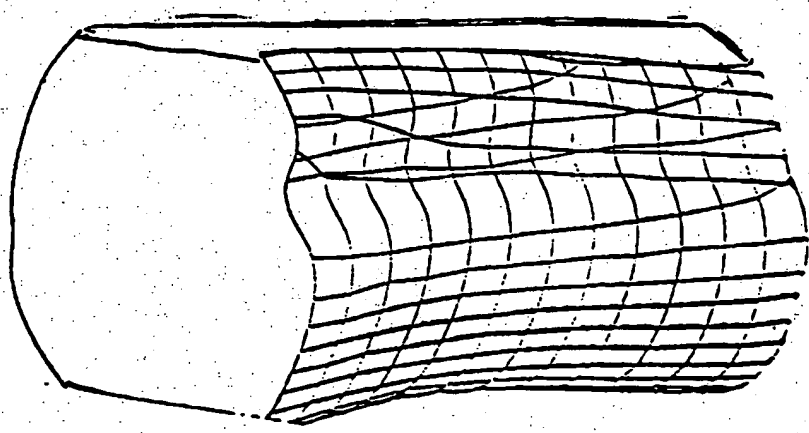
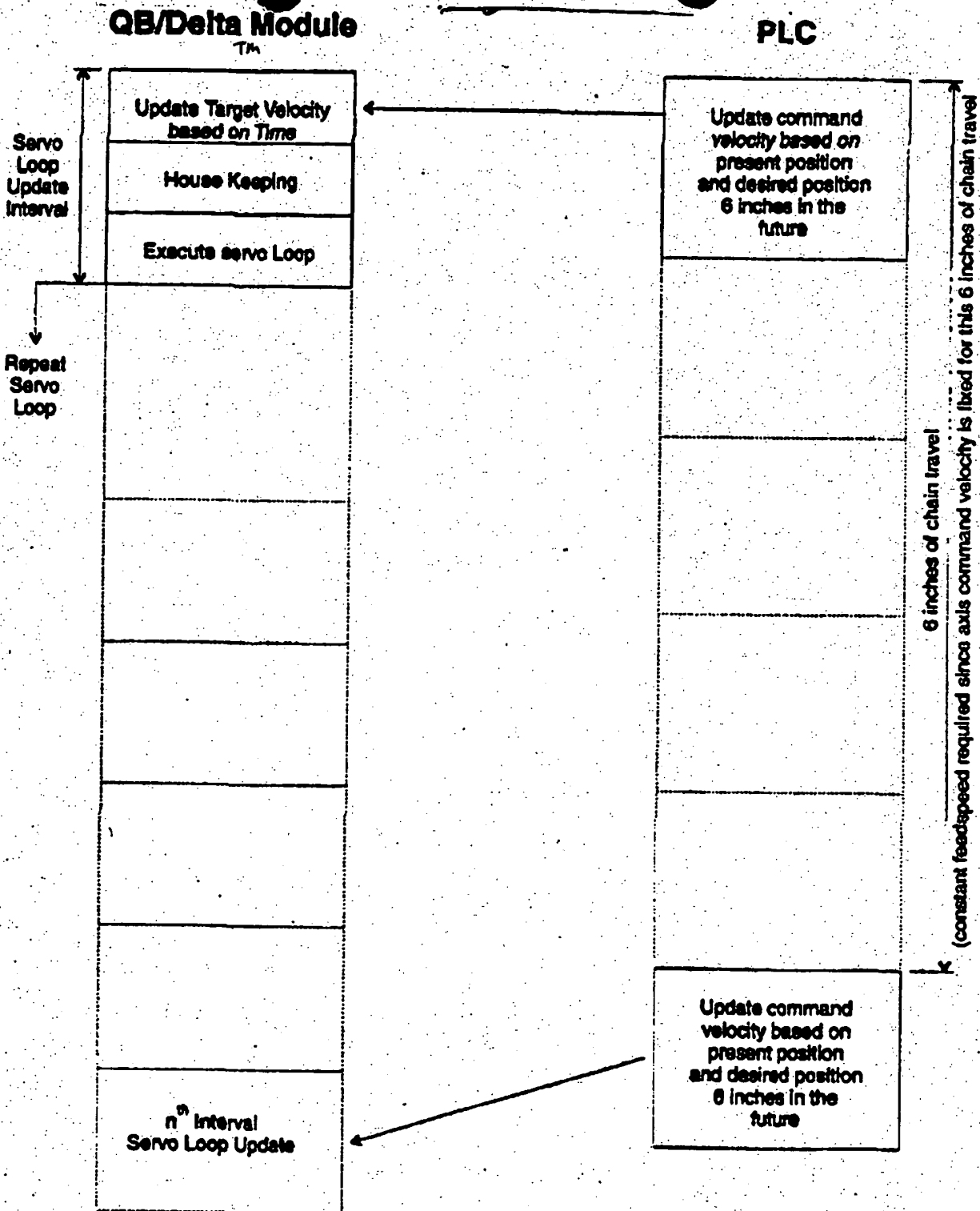


FIG. 1a

08822947.032197



NOTE: This drawing depicts functionality only.

This is not an exact representation of the task divisions within the motion controller

FIG. 2

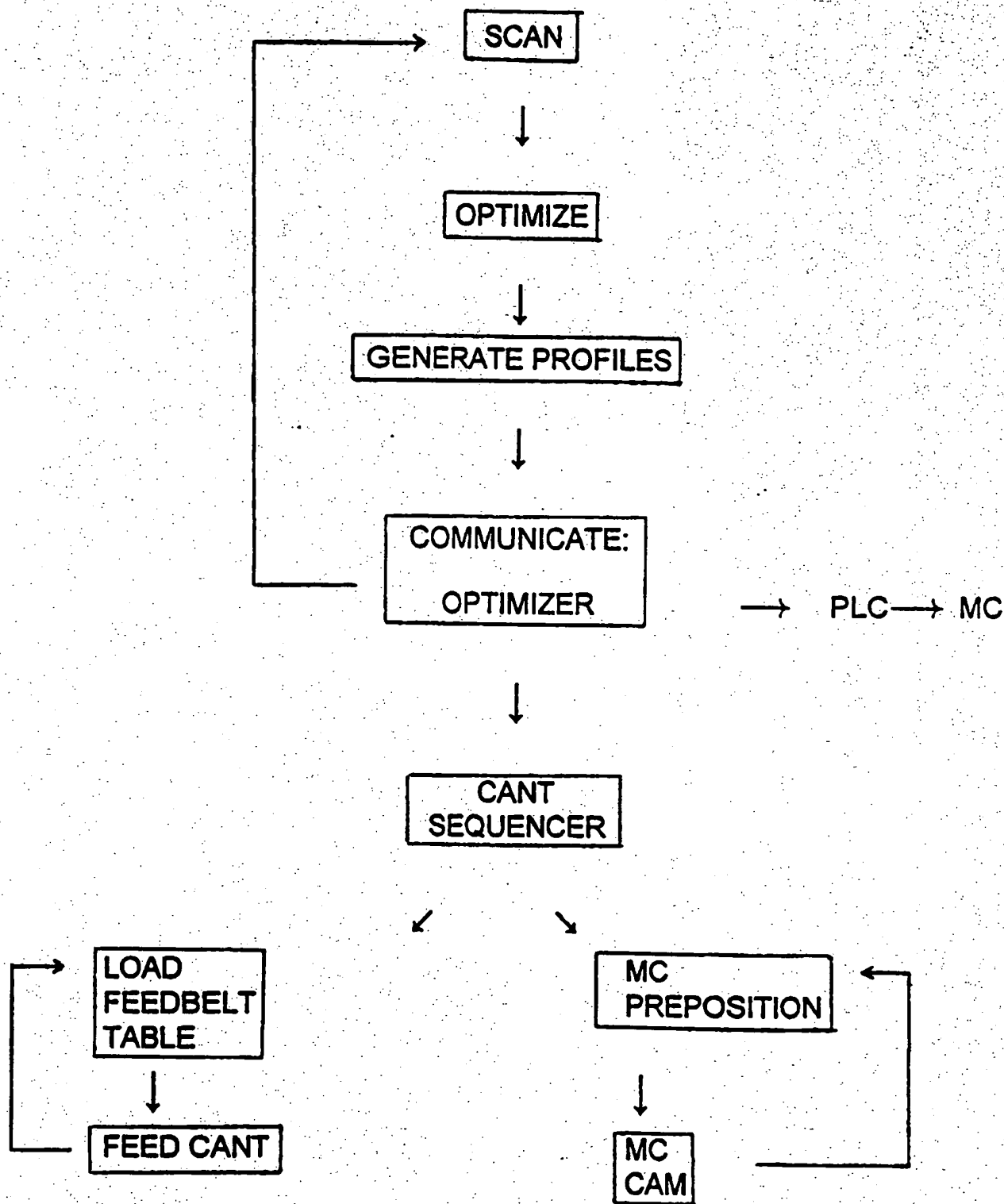


FIG. 3

Original Points

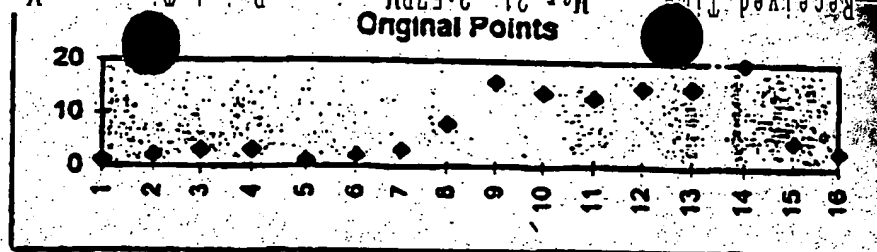


FIG. 4a

1. Generate Polynomial

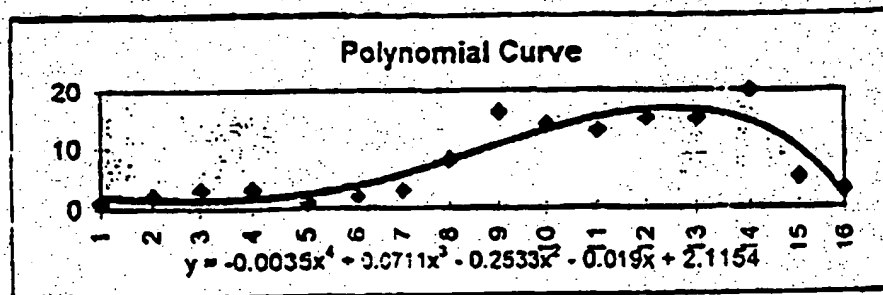


FIG. 4b

2. Calculate discrete points

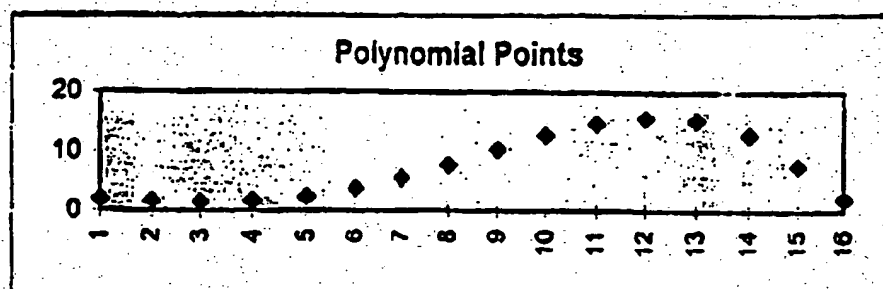


FIG. 4c

3. Apply machine constraints

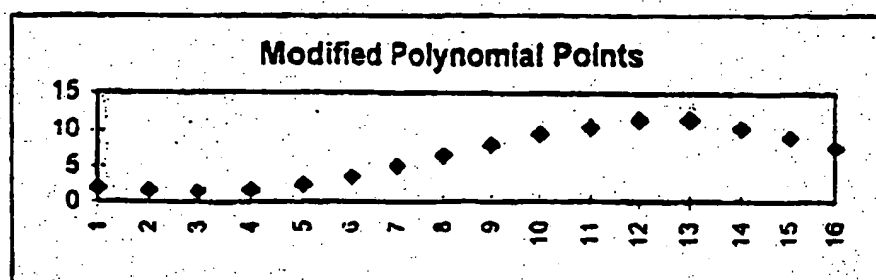


FIG. 4d

4. Re-generate polynomial

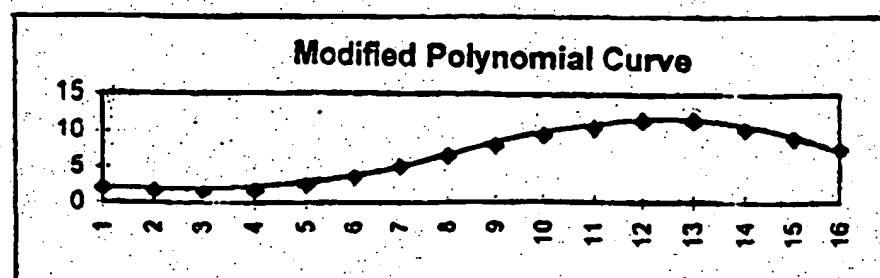
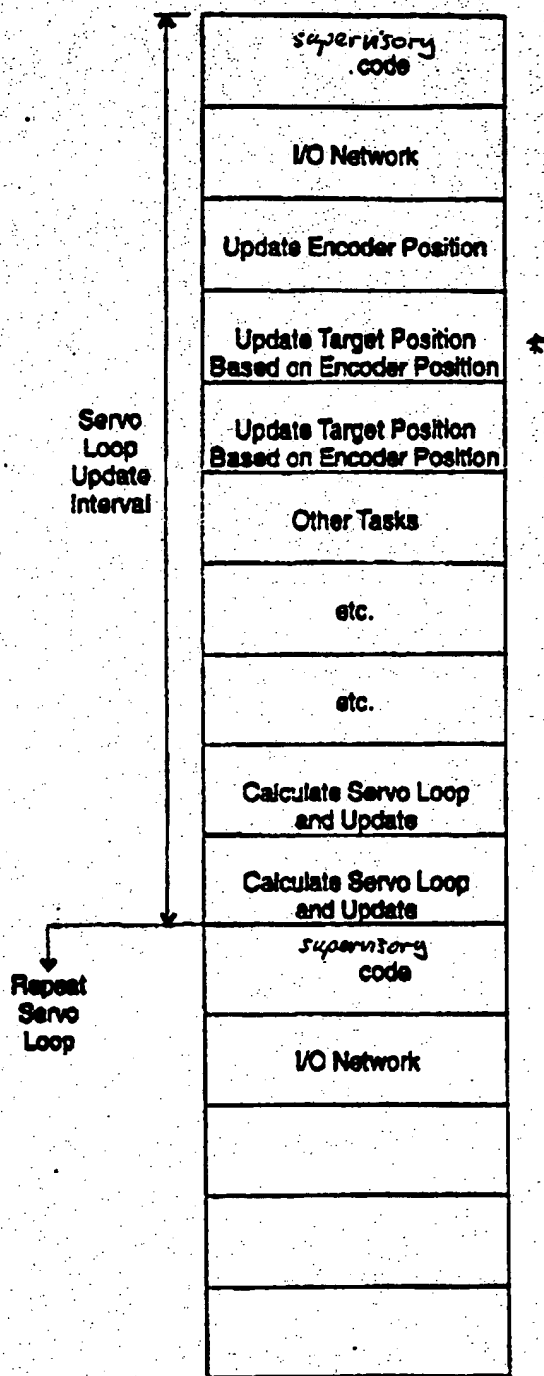


FIG. 4e

202500 24622880

MC Motion Control



NOTE: This drawing depicts functionality only.

This is not an exact representation
of the task divisions within the motion
controller

FIG 5a

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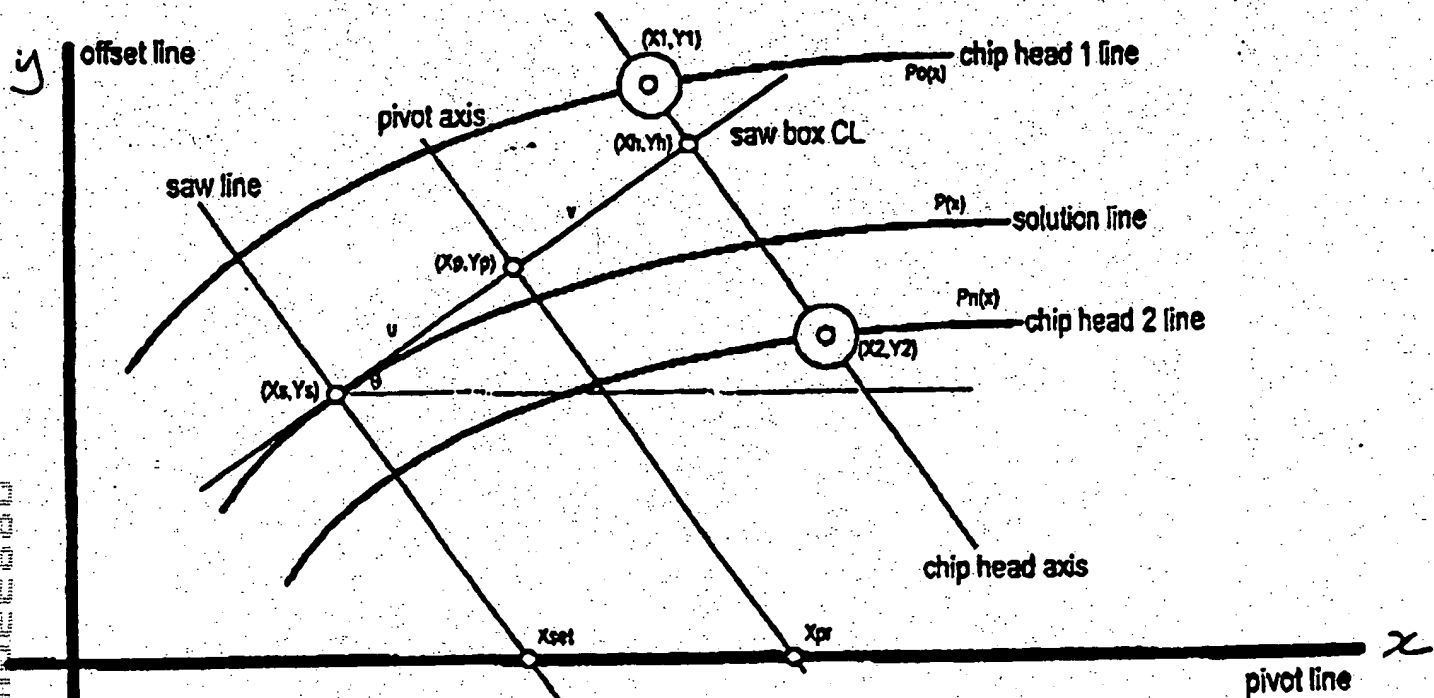
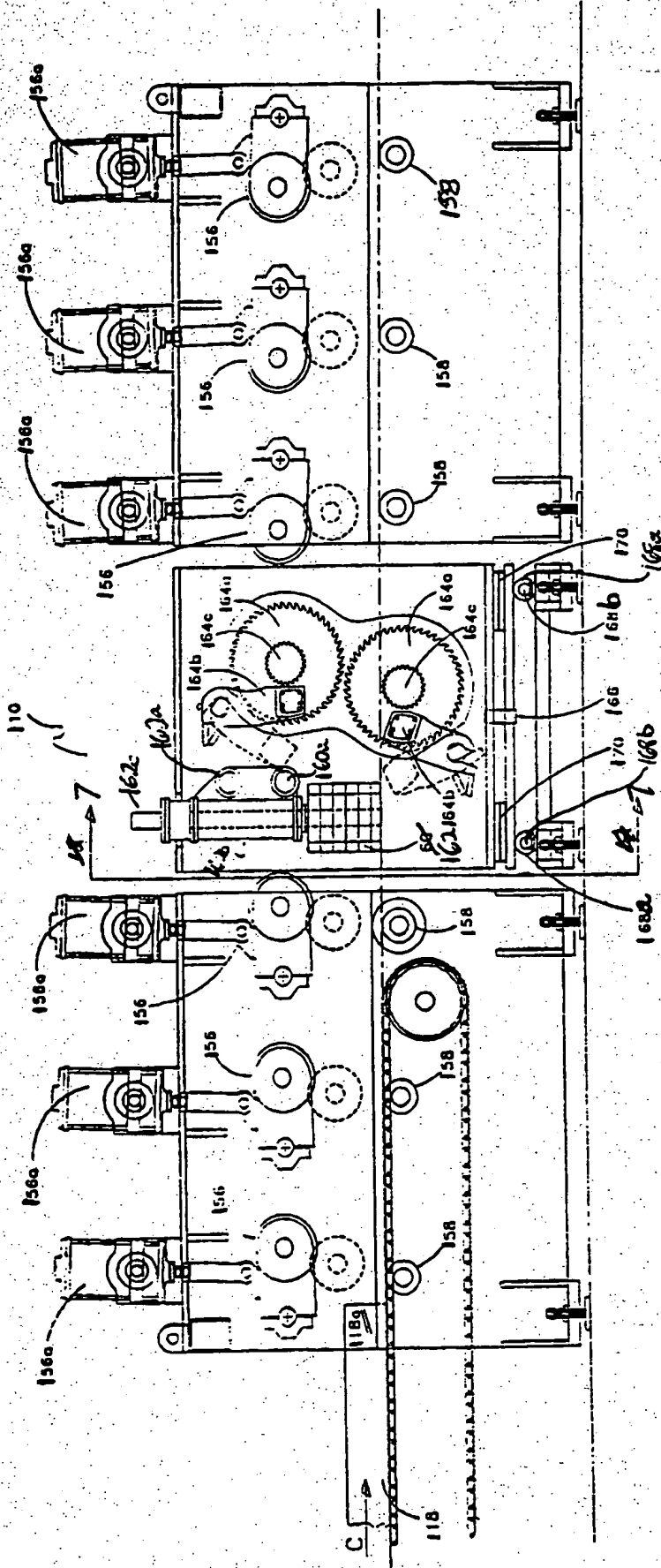


FIG.5b

462280" 4622830

FIG. 6



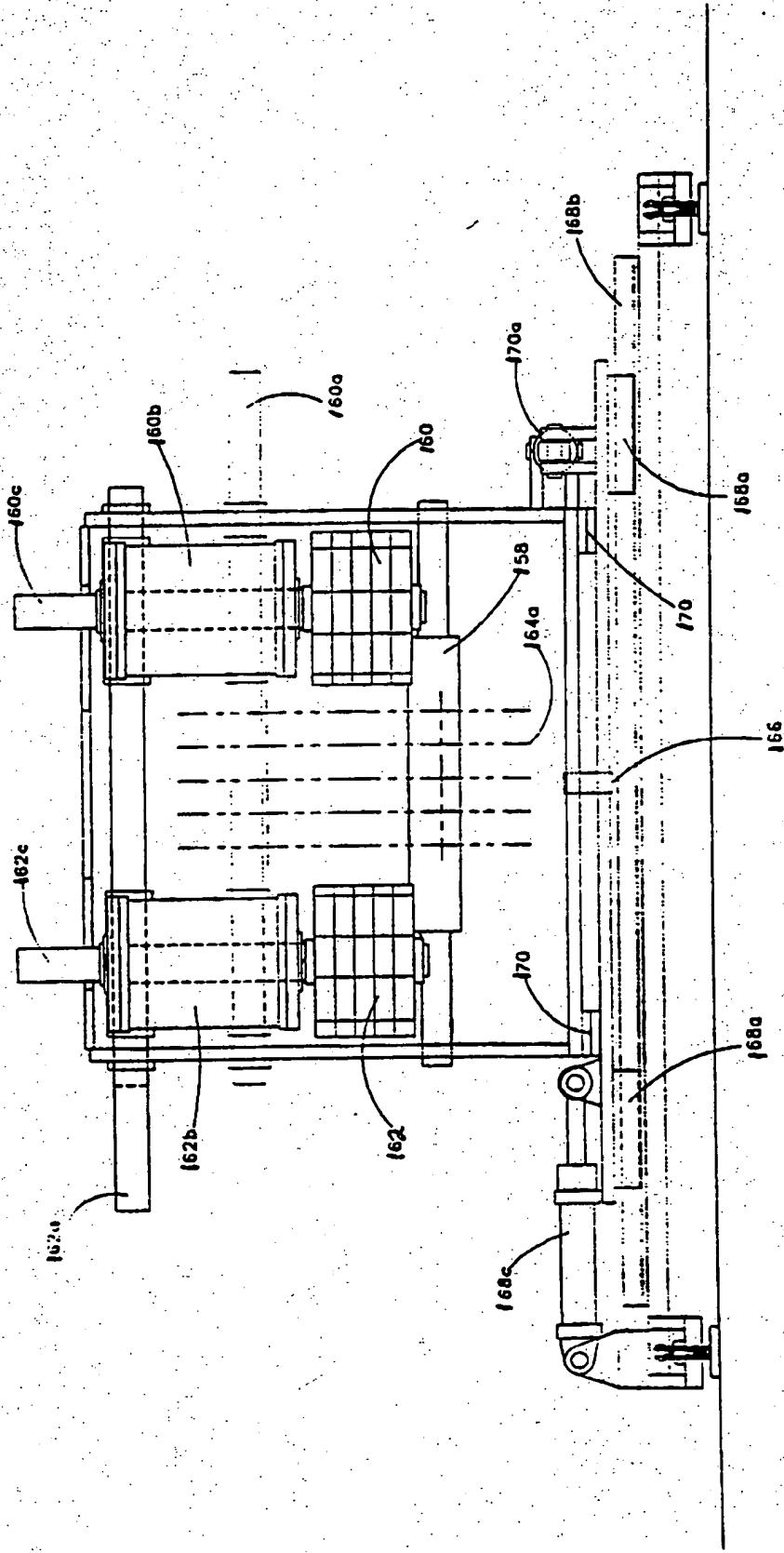
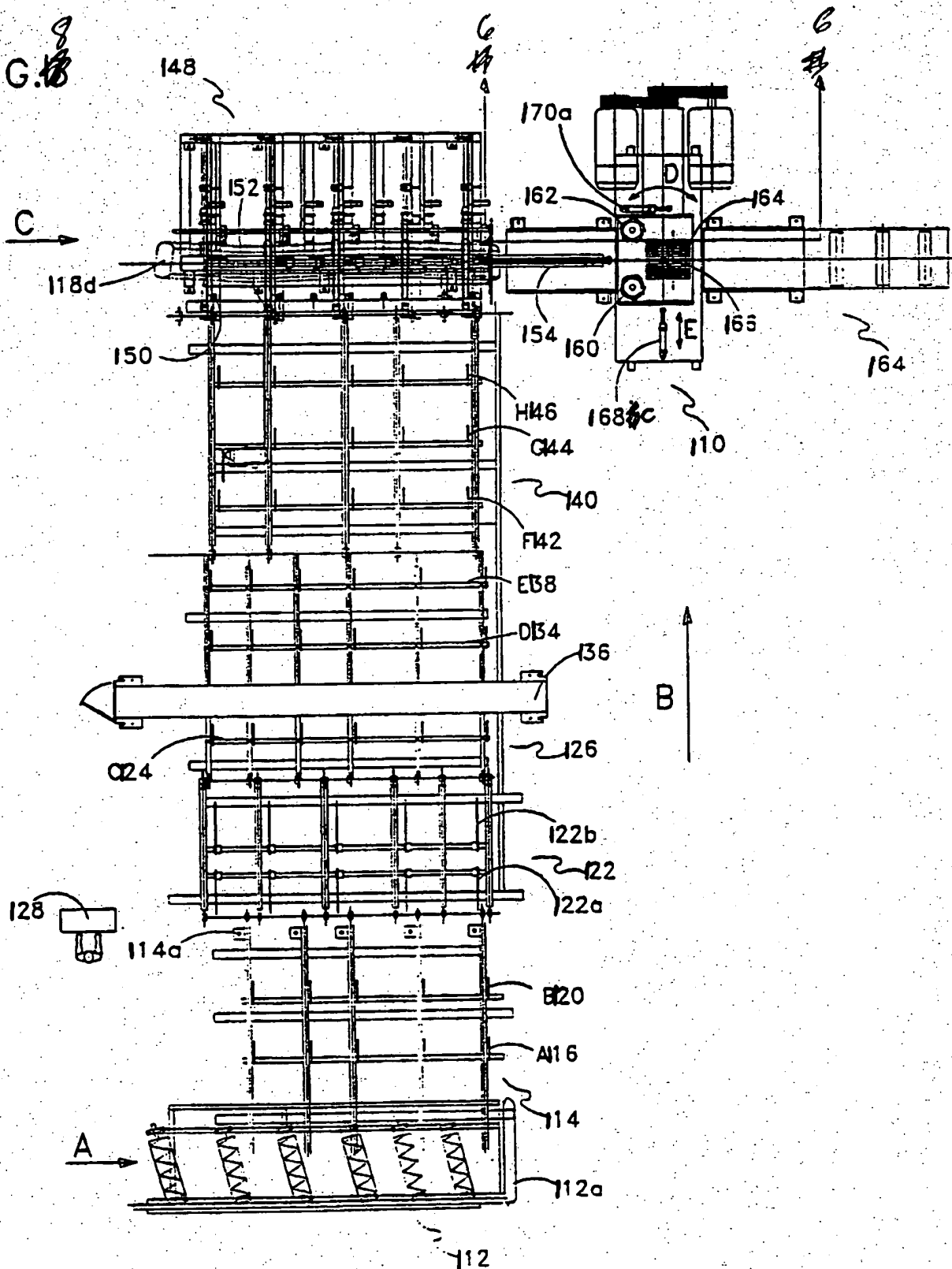


FIG. 7

SECRET

FIG. 1



45 F2ED 44622830

FIG. 14

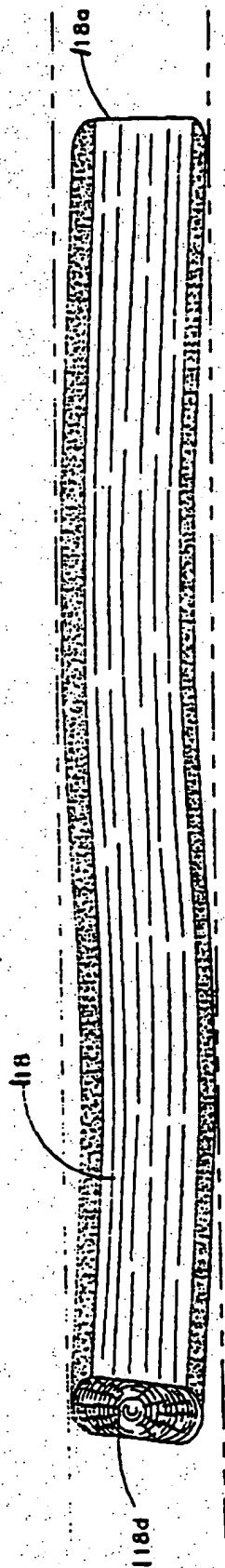
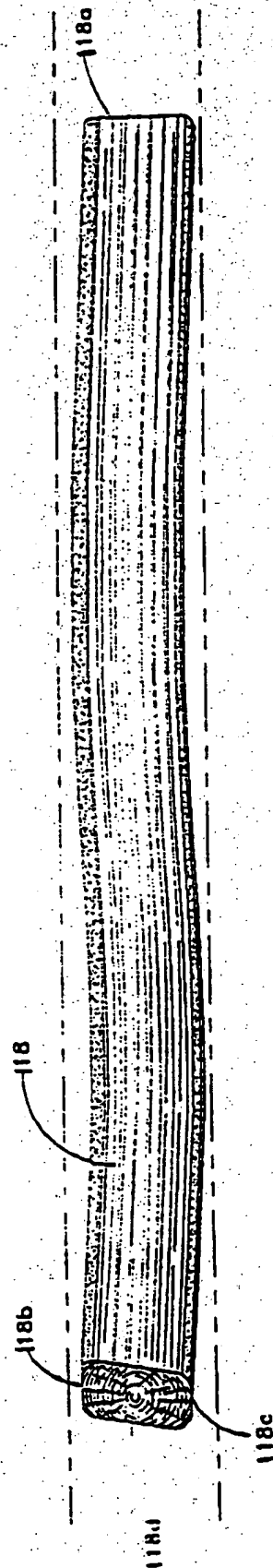


FIG. 14a



Mar. 21. 3:25PM

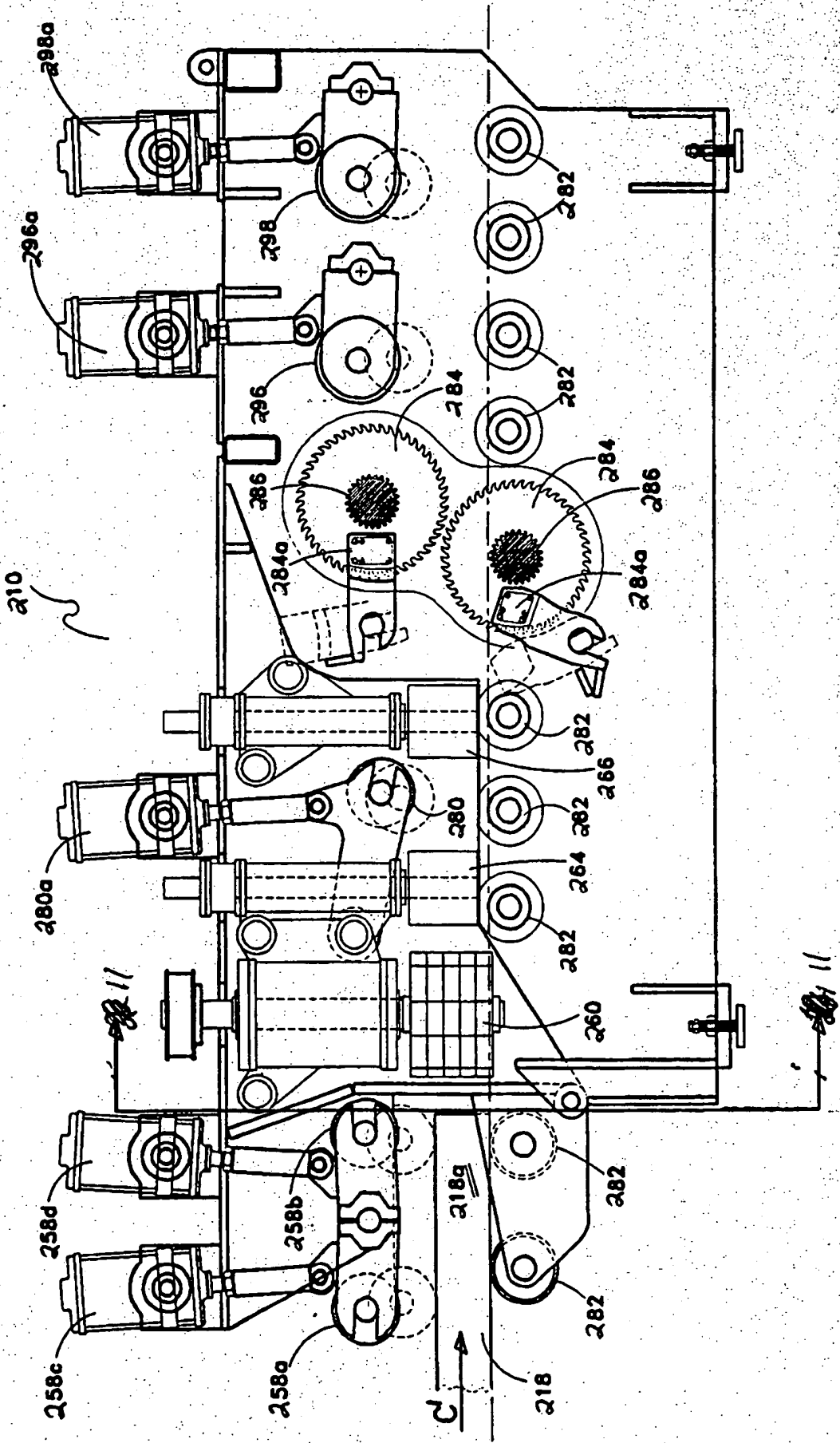
Print Time

Mar. 21. 2:57PM

Received Time

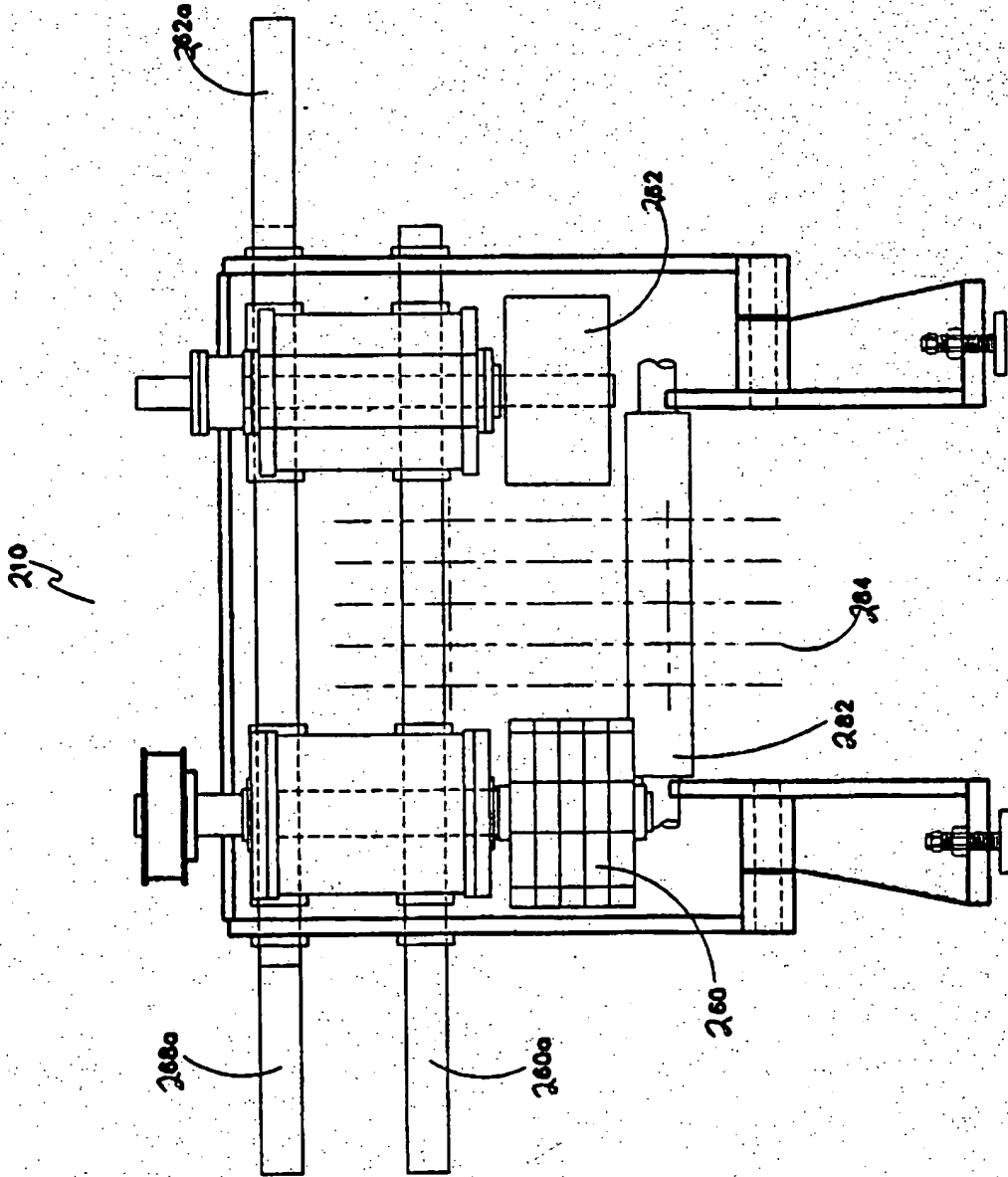
746228/80

FIG. 28



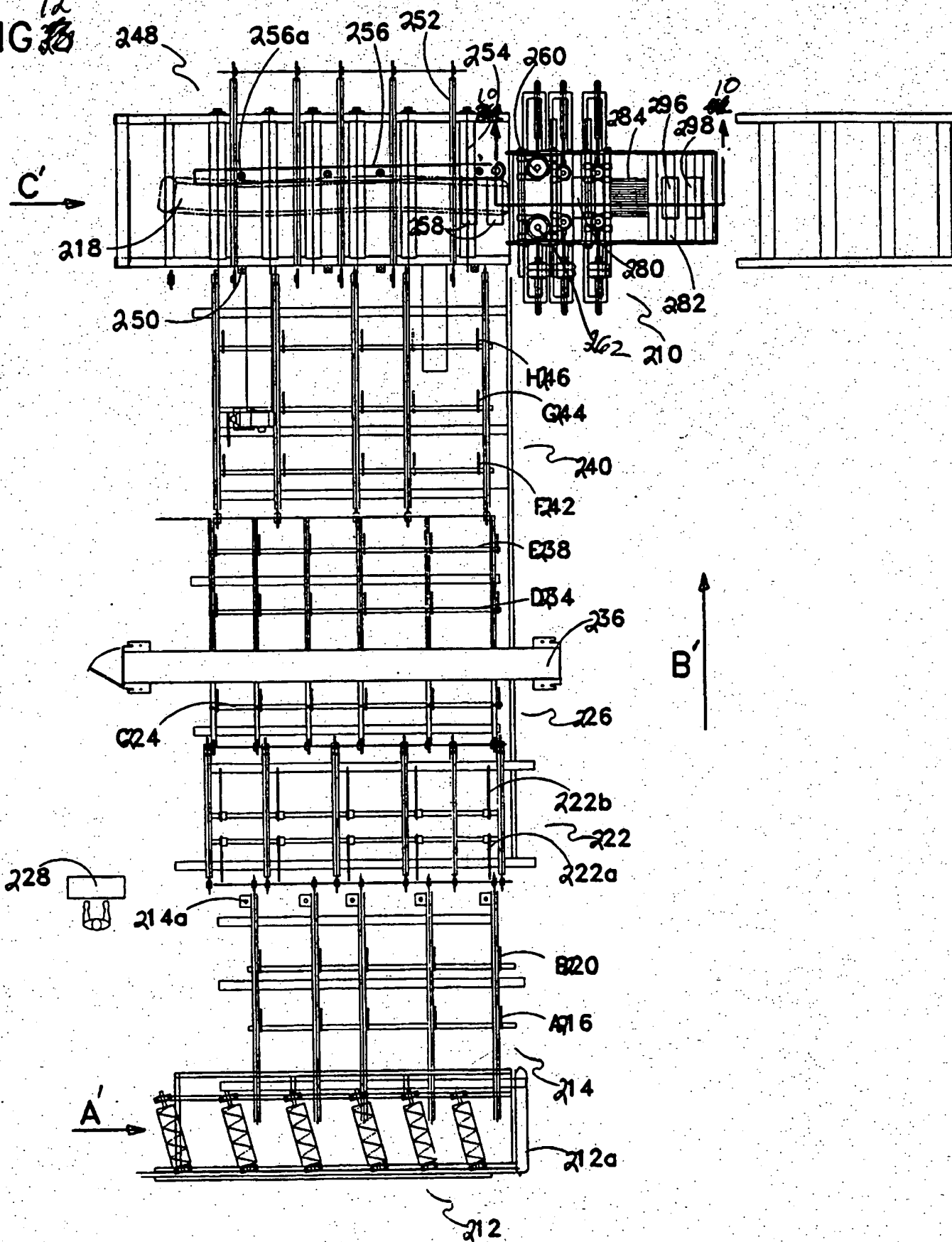
47622980

FIG. 2A



Mar. 21. 3:25PM

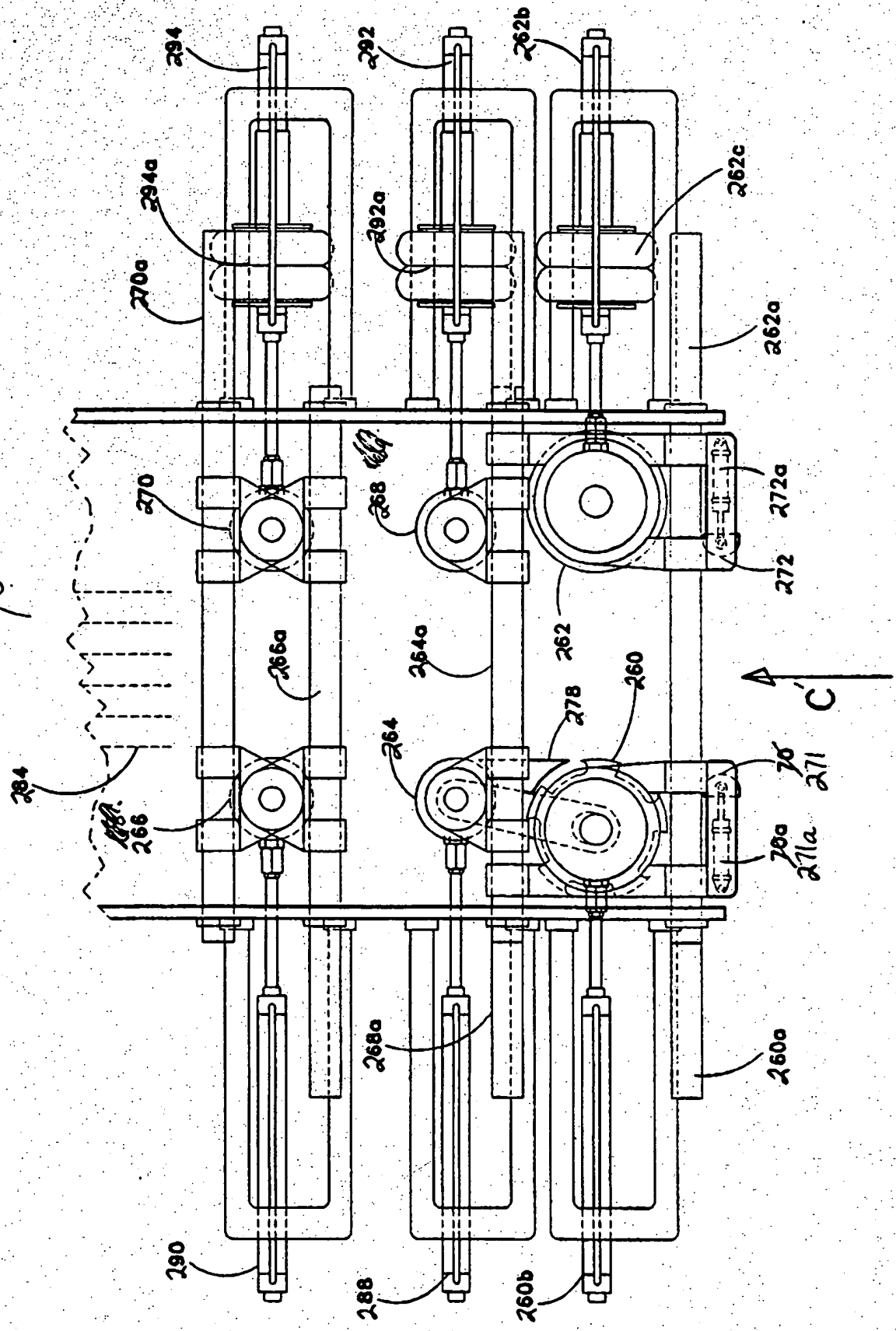
FIG 12



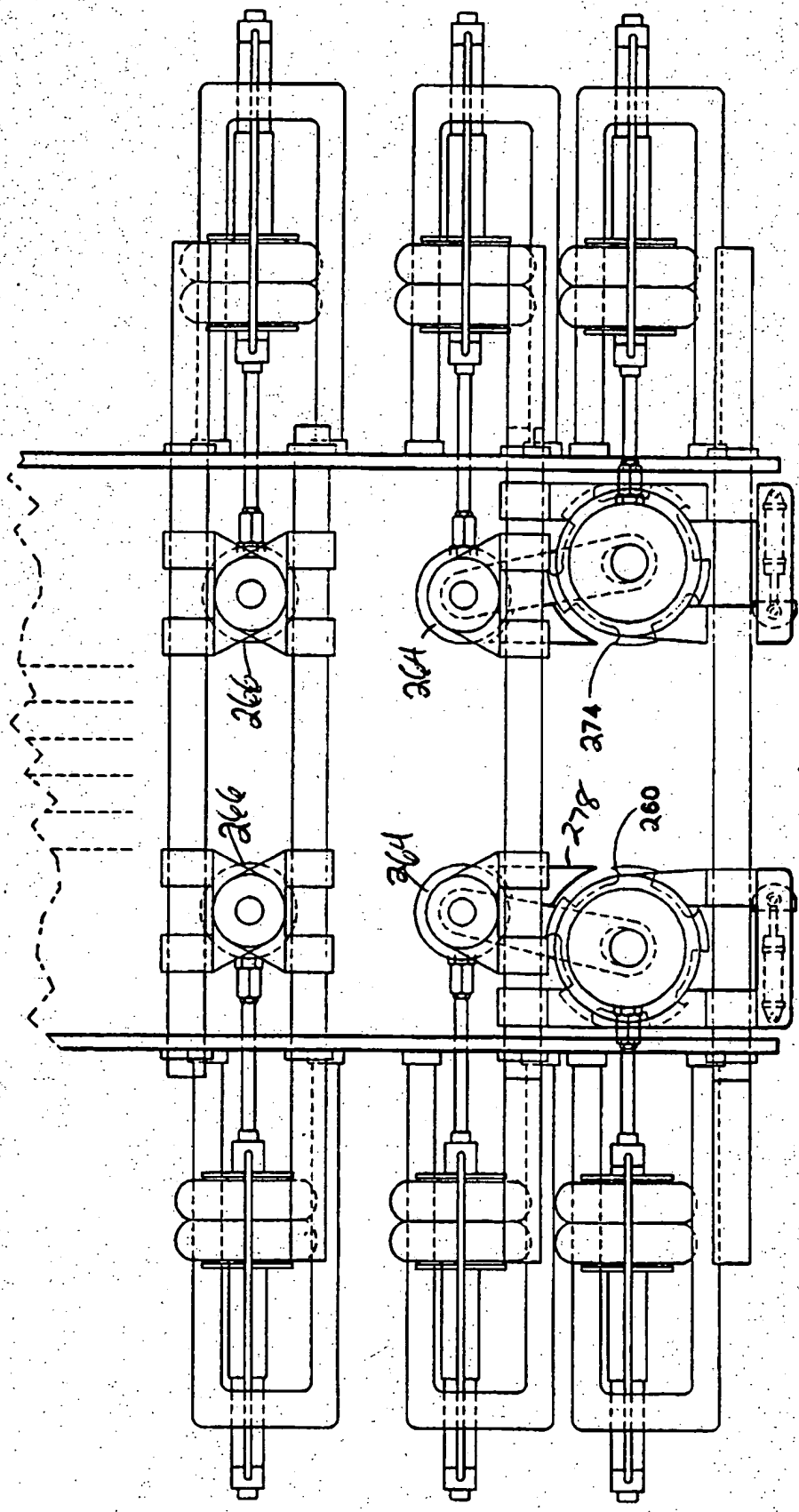
46722947

FIG 13

210



461250" 21622880

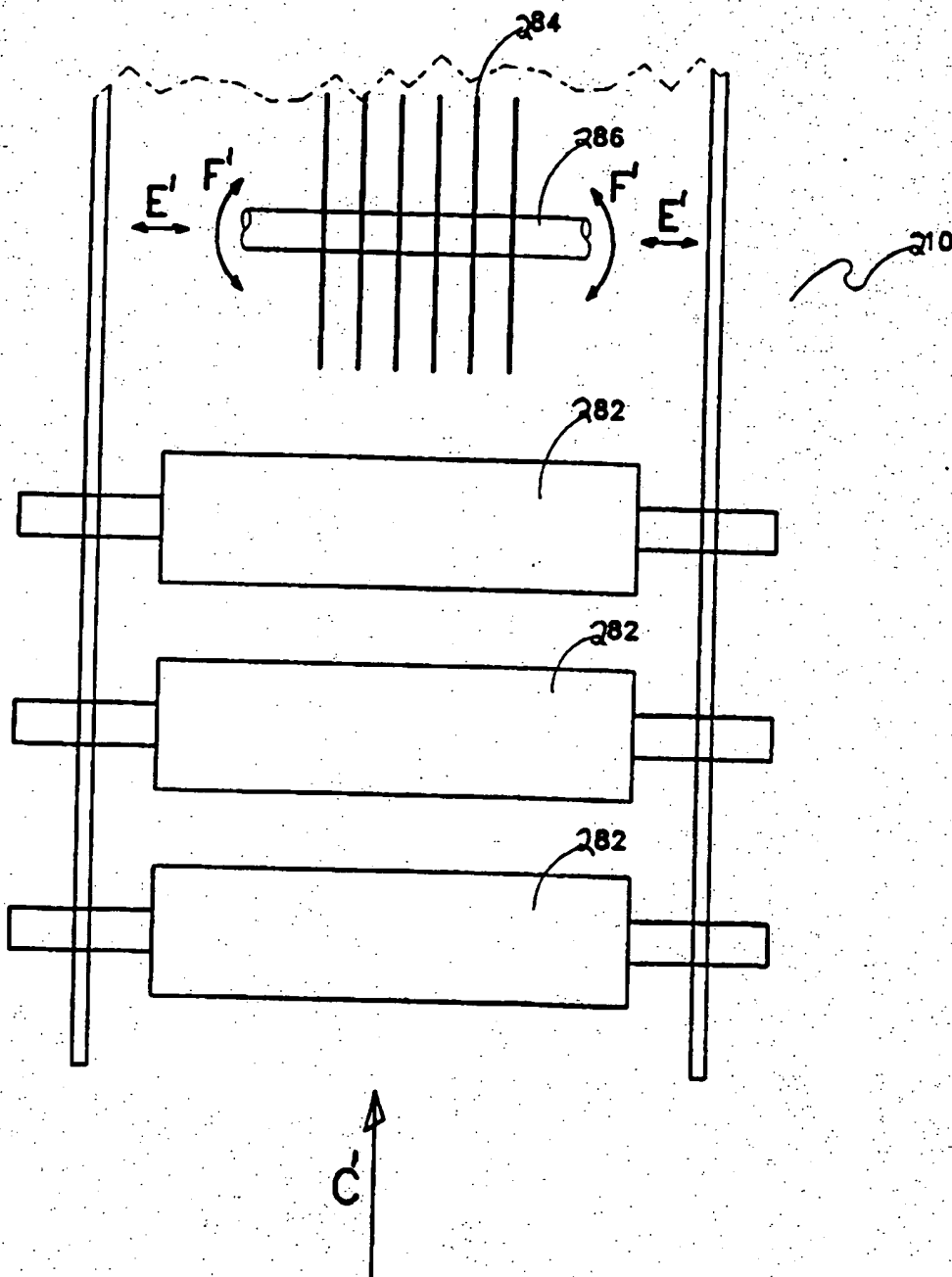


210

461250 44622880

FIG 11

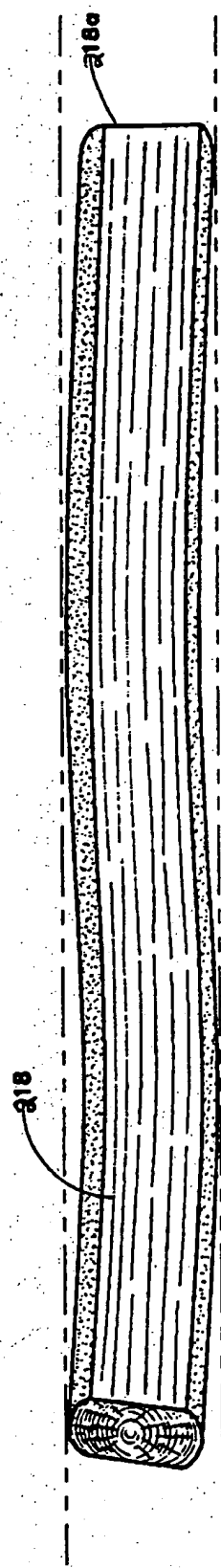
FIG. 15



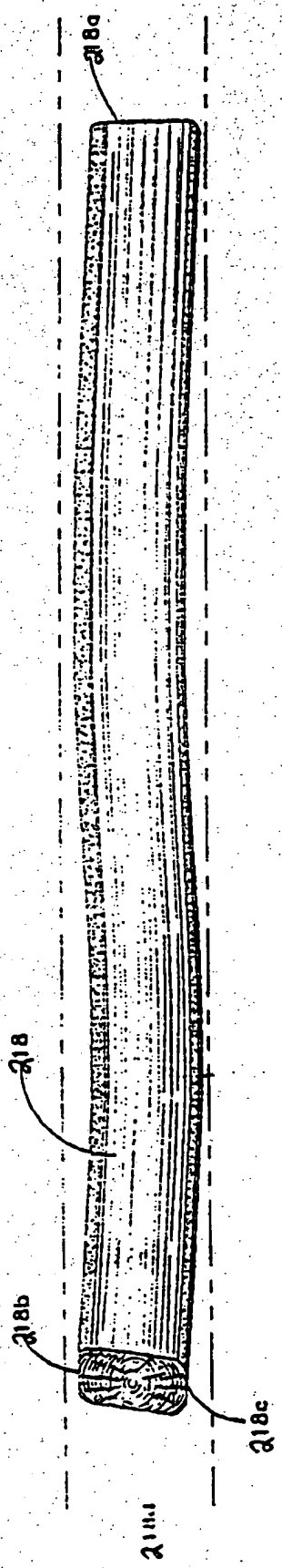
0822947.032197

467220" 21522880

16
FIG. 27



17a
FIG. 27b



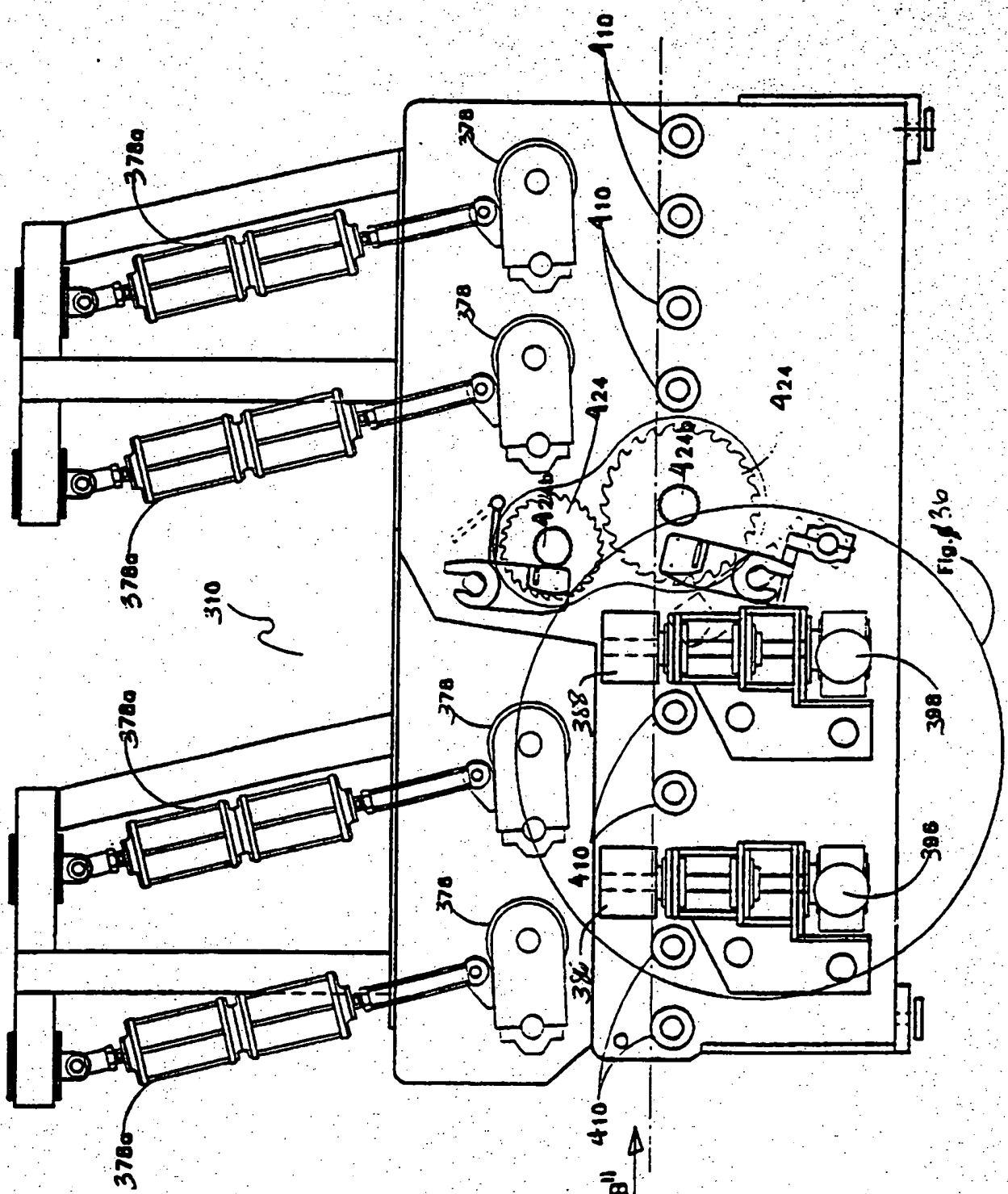
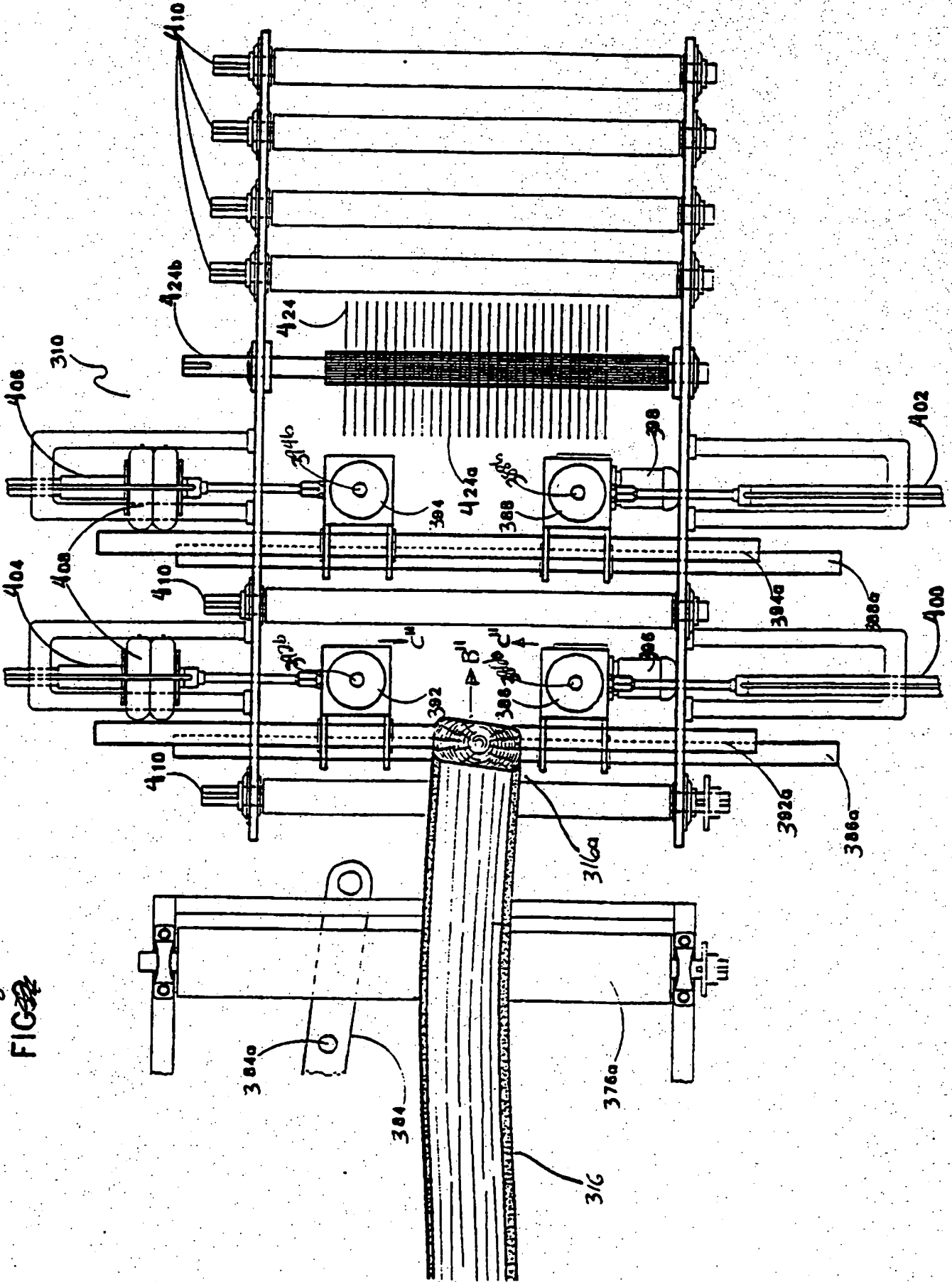


FIG. 3

17

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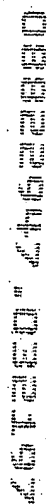


FIG. 33

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FIG 20

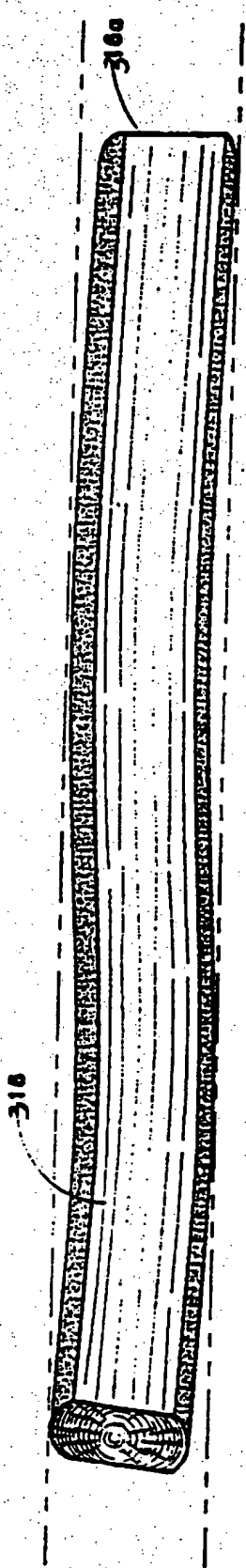
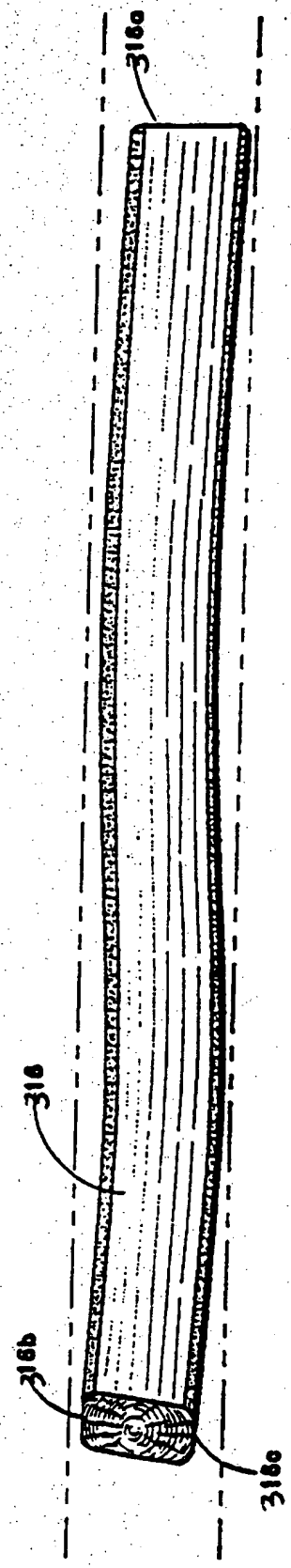


FIG 20a



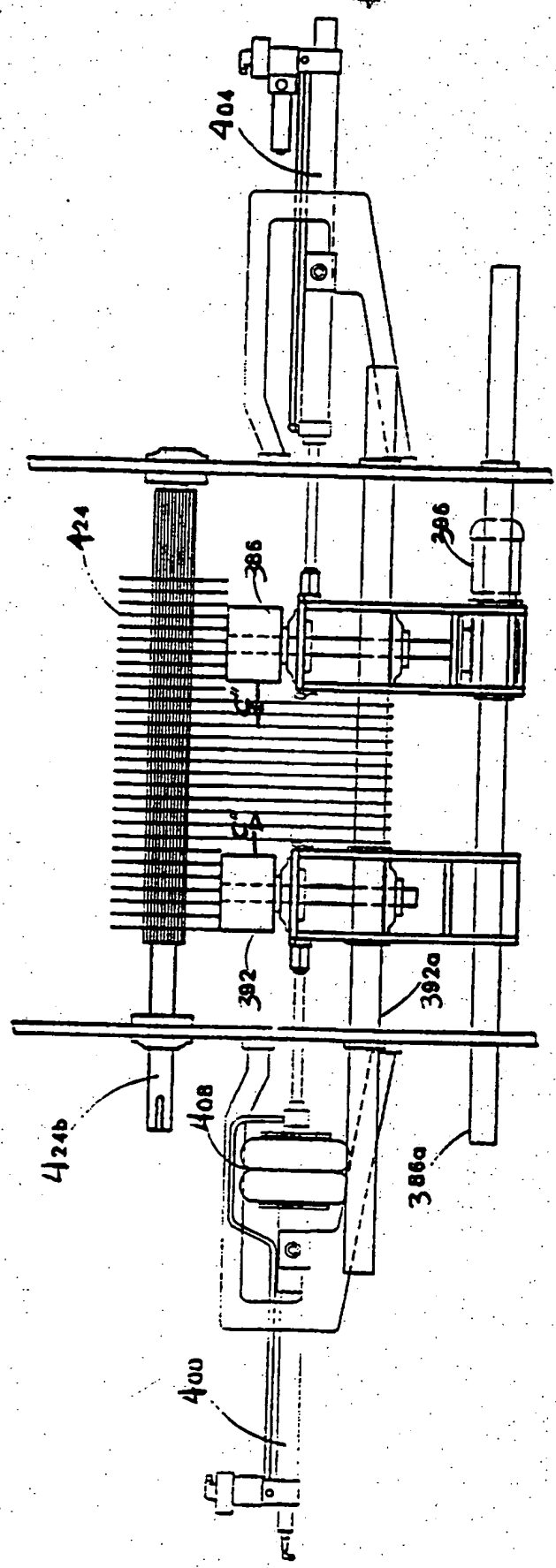
Received Time Mar. 21. 2:57PM Print Time Mar. 21. 3:23PM

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FIG 21

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FIG. 2

